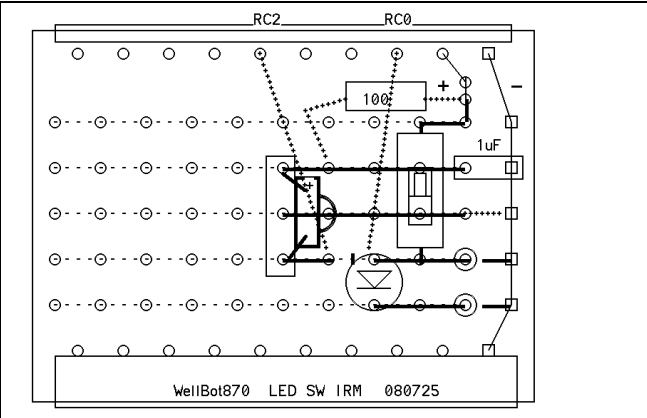
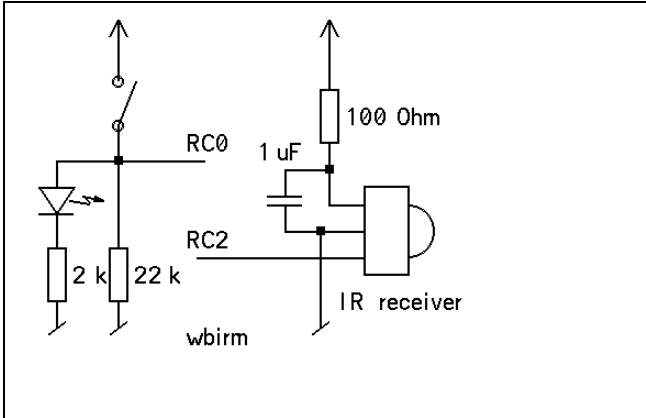


Test environment for the WellBot

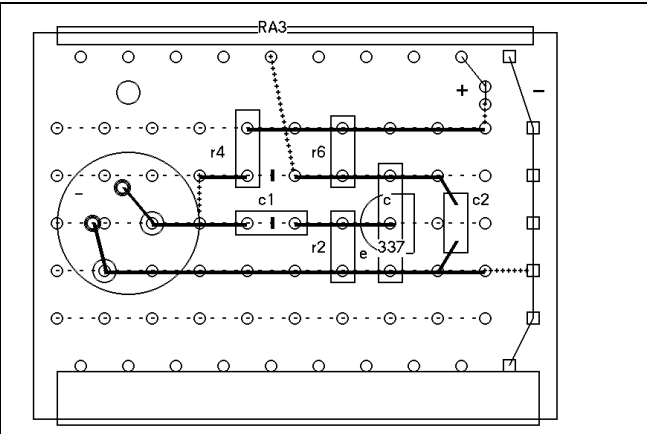
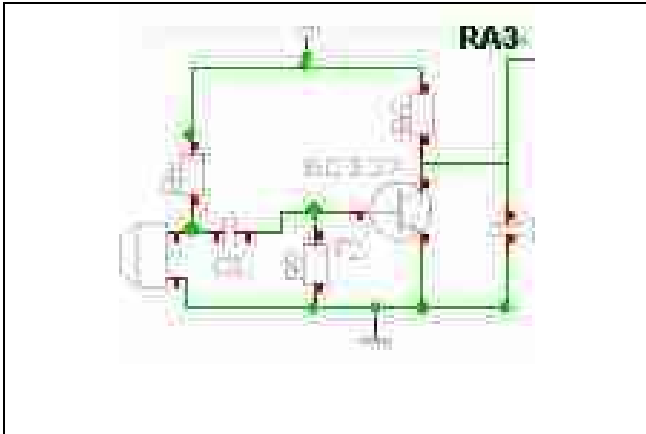
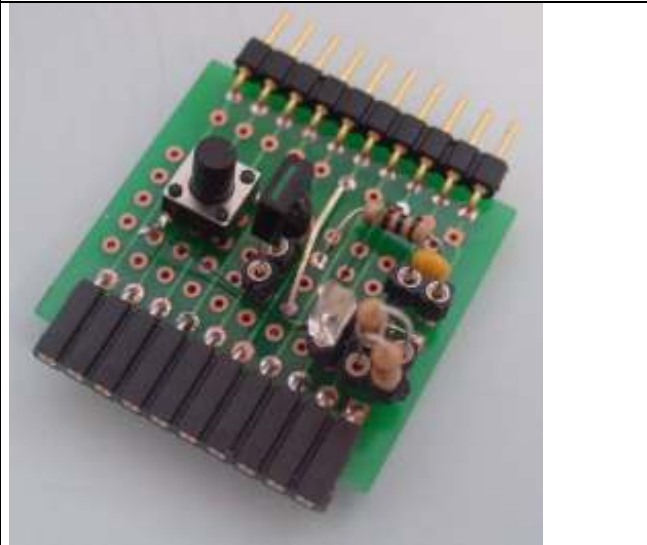
The Wellbot is a nice robot using the 16F870/16F882. It has two stepping motors, two distance sensors and a microphone. Both IR sensors and microphone need software adjustment depending on the task

<p style="text-align: right;">wbdist</p>	
<p>The distance sensor is wired on a small board, together with the transistor that controls the diode current. For saving a processor pin, the buzzer share the same control pin.</p> <p>The light intensity is measured with a timer or waiting loop, see http://www.didel.com/doc/sens/DoclrLog.pdf (fig3)</p>	

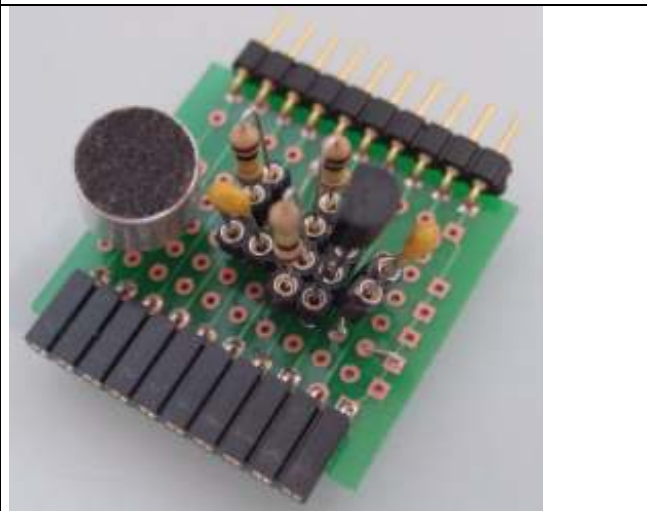


The part of the schematic with the IR sensor and the push button and LED is straightforward to cable.

RC0 port is read as an input when the switch must be read. This may create an invisible blinking if the LED is On by program. LED will be On when the push-button is depressed. These minor drawbacks save a processor pin.

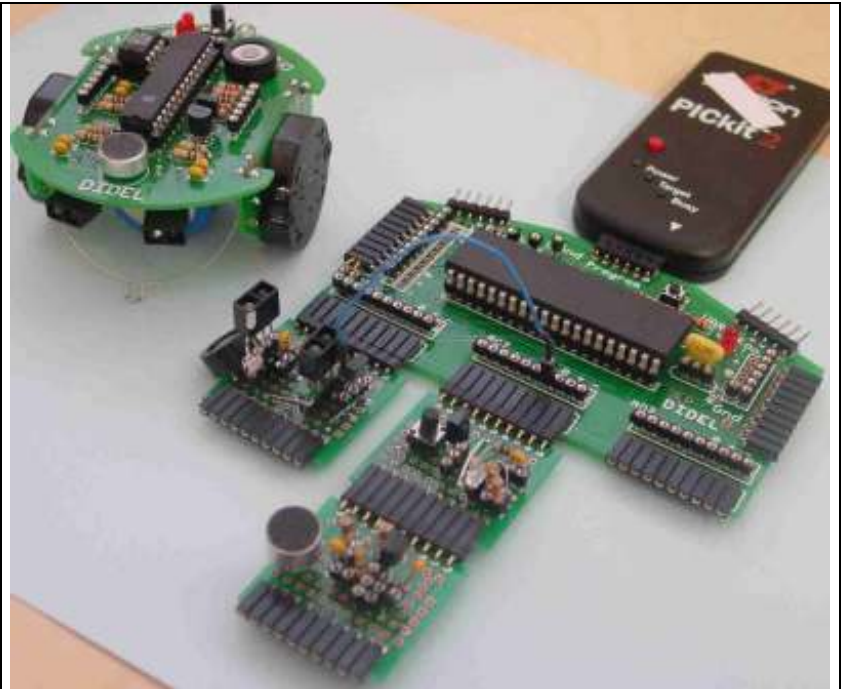


The original microphone schematic is primitive. It is easy not to adjust the resistances, and if a better schematic has to be tested, it is easy.



The wellbot has a serial communication using the Rx/Tx pins. No need to wire it, the Pickit2 uart mode will take care of this.

For the stepping motor, we consider less useful to do it, now we have efficient routines. But of course, we did the test fixtures in the past for different projects.



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